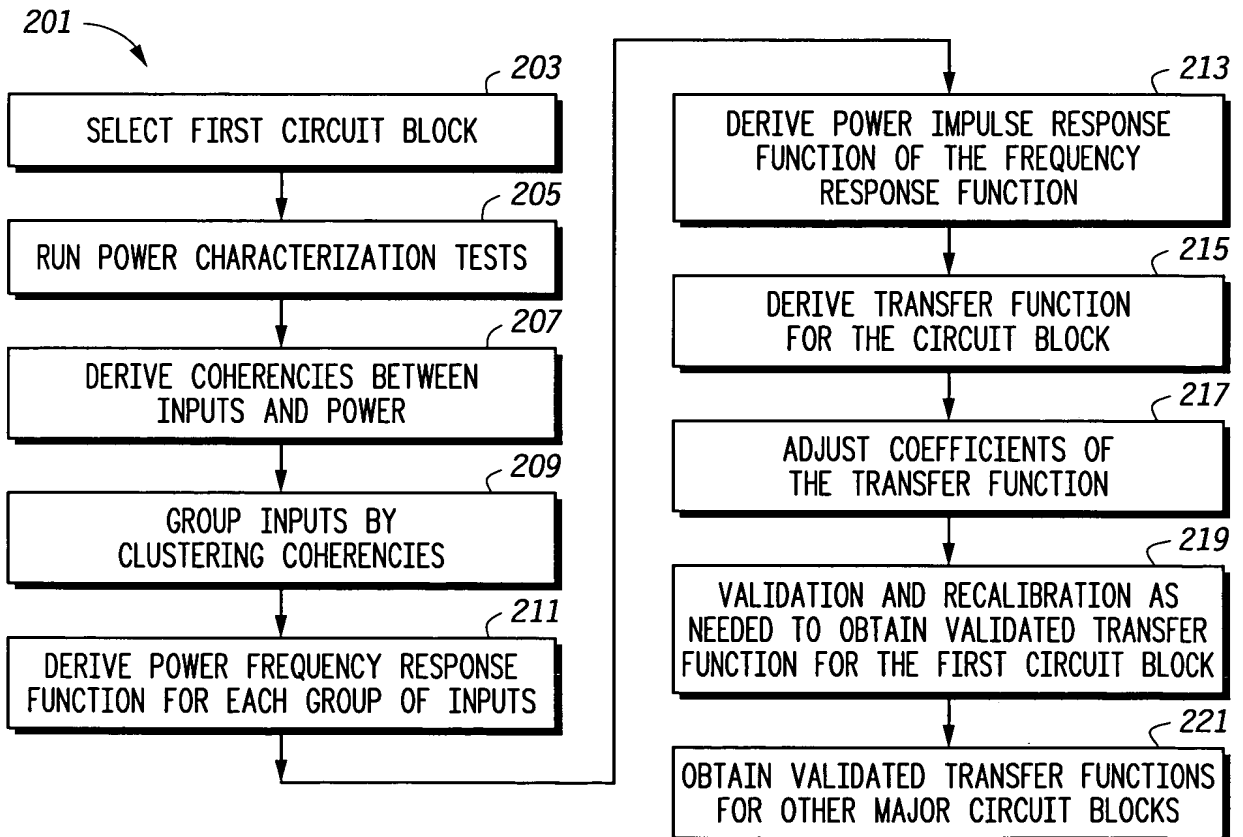


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	T <sub>1</sub>	T <sub>2</sub>	T <sub>3</sub>	T <sub>4</sub>	T <sub>5</sub>	T <sub>6</sub>	T <sub>7</sub>	T <sub>8</sub>
g <sub>1</sub> (T)	0	0	1	1	0	1	0	1
g <sub>2</sub> (T)	0	0	0	1	1	0	1	1
Y <sub>g1</sub> (T)	0	0	4	6	2	4	2	4
Y <sub>g2</sub> (T)	0	0	0	3	3	1	4	3
Y <sub>T</sub> (T)	0	0	4	9	5	5	6	7

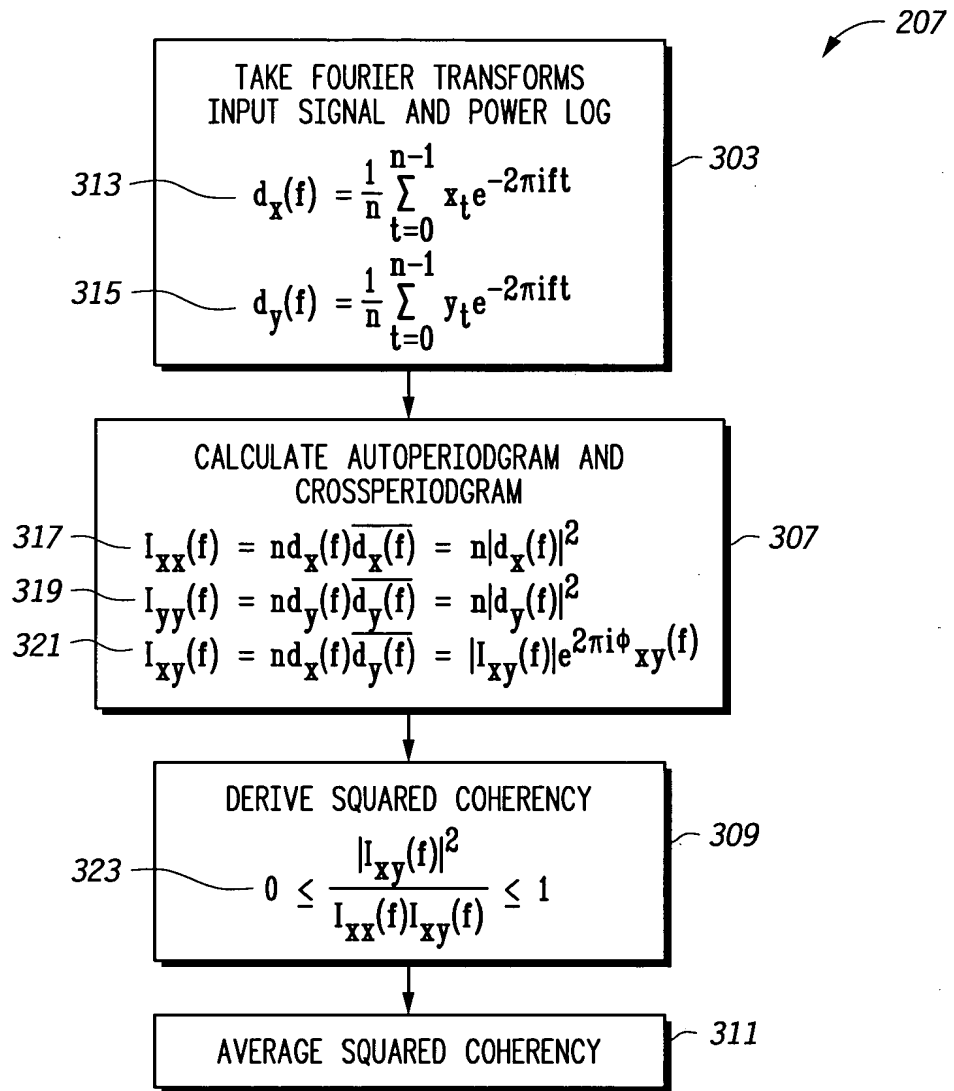
$$Y_T(T) = \underbrace{4g_1(T) + 2g_1(T-1)}_{Y_{g1}} + \underbrace{3g_2(T) + 1g_2(T-2)}_{Y_{g2}}$$

**FIG. 1**



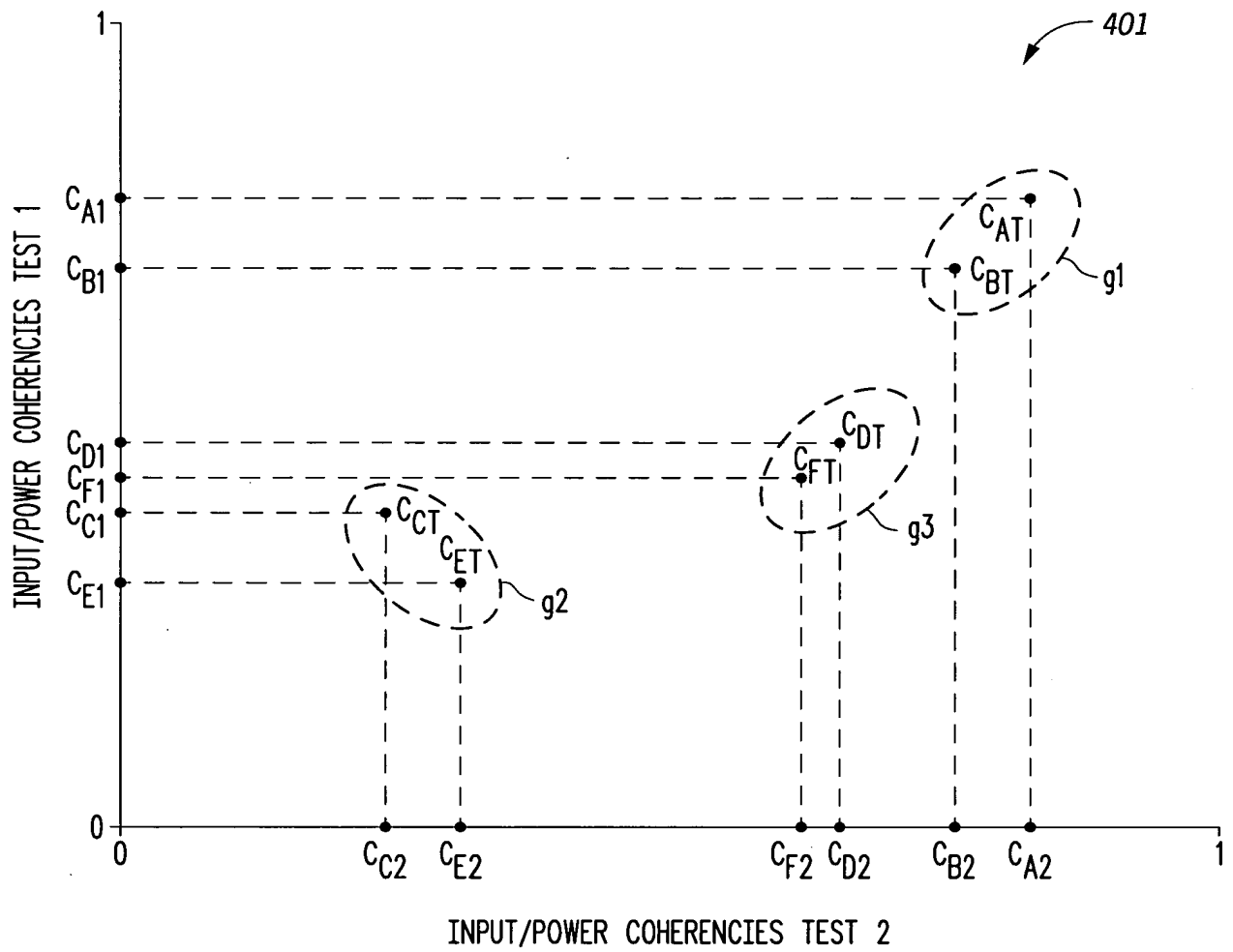
**FIG. 2**

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**FIG. 3**

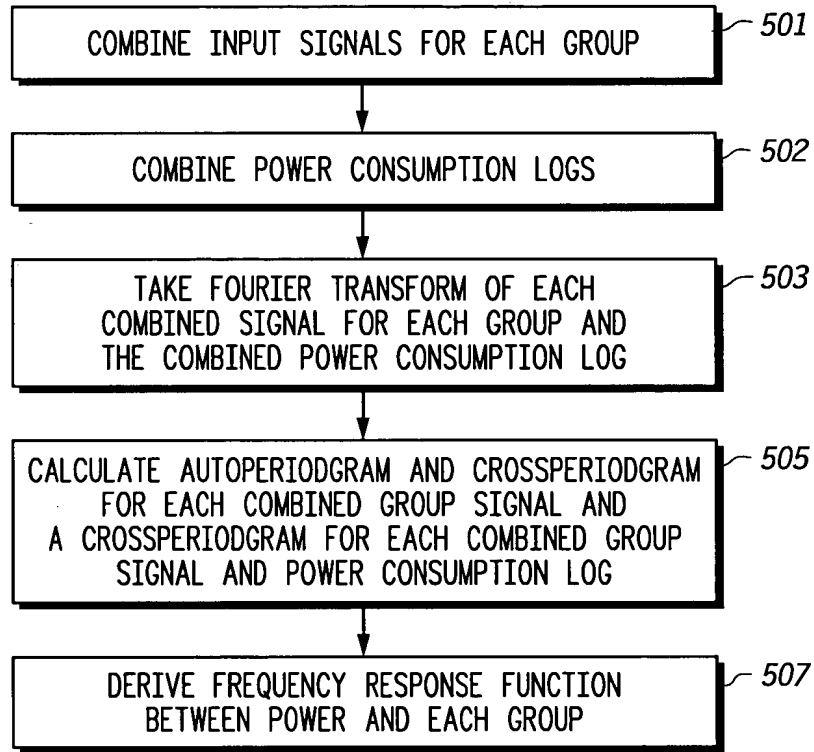
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**FIG. 4**

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**FIG. 5**

$$\begin{aligned}
 215 \quad 605 \quad Y_T &= \frac{a}{1 + bB} g1 + (c + dB)g2 \\
 603 \quad v_k &= \int H(f)e^{2\pi ifk} df \\
 213 \quad 601 \quad \left\{ \begin{array}{l} I_{x_1 y}(f) = H_1(f)I_{x_1 x_1}(f) + H_2(f)I_{x_1 x_2} + \dots + H_n(f)I_{x_1 x_n} \\ I_{x_2 y}(f) = H_1(f)I_{x_2 x_1}(f) + H_2(f)I_{x_2 x_2} + \dots + H_n(f)I_{x_2 x_n} \\ \vdots \\ I_{x_n y}(f) = H_1(f)I_{x_n x_1}(f) + H_2(f)I_{x_n x_2} + \dots + H_n(f)I_{x_n x_n} \end{array} \right.
 \end{aligned}$$

**FIG. 6**

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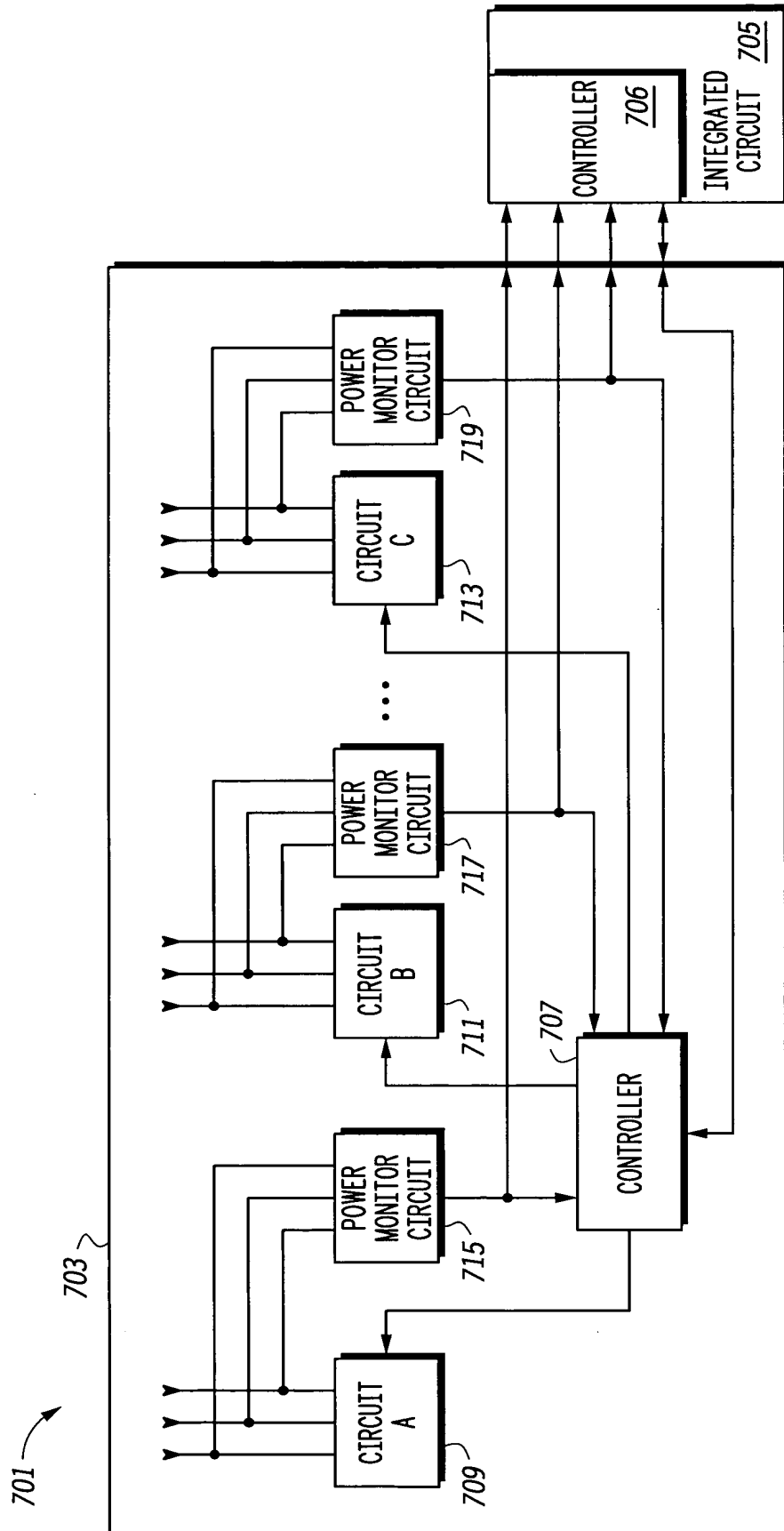


FIG. 7